

EAST Search History

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
S1	13	(laser with weld\$4) and ((multi-axial)or (multi-axial) or (multi axial)) and manipulator	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2008/12/12 08:16
S2	10	("4694139" "4891765" "4967127" "5006999" "5723962" "5737500" "6070109" "6163124" "6356806" "7130718").PN.	US-PGPUB; USPAT; USOOR	ADJ	ON	2008/12/12 08:19
S3	27	("3528424" "3642352").PN. OR ("4174154").URPN.	US-PGPUB; USPAT; USOOR	ADJ	ON	2008/12/12 08:23
S4	11	(laser with weld\$4) and (robot with ((multi-axial)or (multi-axial) or (multi axial))) and manipulator	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2008/12/12 08:29
S5	9	("4733048" "4840303" "5142118" "5266770").PN. OR ("5731566").URPN.	US-PGPUB; USPAT; USOOR	ADJ	ON	2008/12/12 08:30
S6	8	(("4855565") or ("4626999") or ("20020104834") or ("20020170889")).PN.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2008/12/12 09:10
S7	1381	(219/121.63).COLS.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2008/12/12 09:33
S8	163936	("219").CLAS.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2008/12/12 09:35
S9	3490	S8 and robot	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2008/12/12 09:35

S10	22	S9 and ((multi-axial) or (multi-axial) or (multi-axial))	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2008/12/12 09:36
S11	265	S9 and manipulator	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2008/12/12 09:41
S28	1950	(219/121.6).OCLS.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2009/01/30 16:44
S29	821	(219/121.78).OCLS.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2009/01/30 16:44
S30	2013	(219/121.64).OCLS.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2009/01/30 16:45
S32	75	S28 and S29	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/01/30 16:46
S33	298	(700/166).OCLS.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2009/01/30 16:54
S36	6	(laser) with((multi-axial) or (multi-axial) or (multi-axial)) with manipulator	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 10:02
S37	9	(laser with weld\$4) and (robot with ((multi-axial) or (multi-axial) or (multi-axial))) with manipulator	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 10:02

S45	4067	welding with laser with fix \$3	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 14:50
S46	3	welding with laser with fix \$3 focal	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 14:50
S47	264	laser with fix\$3 focal	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 14:51
S50	242	laser with fixed focal	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 15:09
S51	141	laser with fixed focal distance	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 15:21
S54	229	(optical or laser) with fixed focal distance	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 15:47
S57	141	laser with fixed focal distance	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/02 17:14
S61	4	laser with weld\$3 with ((fix \$2 angle)or(fix\$2-angle)) with laser beam	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/03 09:27
S62	5	laser with weld\$3 with ((fix \$2 angle)or(fix\$2-angle))	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/03 09:28

S63	400	laser with ((fix\$2 angle) or (fix\$2-angle))	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/03 09:29
S65	2	robot with laser with ((compensat\$3 motion) or (displac\$3 motion))	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/03 16:46
S66	6	robot with laser with ((compensat\$3 with motion) or (displac\$3 with motion))	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/03 16:55
S79	181	robot same (weld\$4 machin\$3) and (move\$4 moving motion displ\$5 translat\$4) with (tool tip! electrode laser) with compensat\$4	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2009/02/04 13:51
S107	6035	((multi-axial) or (multiaxial) or (multi axial)) or manipulator with constant (velocity or speed or movement or motion)	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/04 18:11
S108	5925	((multi-axial) or (multiaxial) or (multi axial)) or manipulator with constant (velocity or speed or movement or motion)	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/04 18:16
S109	516	robot with ((multi-axial) or (multiaxial) or (multi axial)) or manipulator with constant (velocity or speed or movement or motion)	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/04 18:18
S110	406	robot with ((multi-axial) or (multiaxial) or (multi axial)) or manipulator with constant (velocity or speed or movement or motion)	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/04 18:26
S113	30	S110 with weld\$4	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/04 18:35

S114	33	S109 with weld\$4	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/04 18:51
S115	2	((laser with weld\$4) and (robot with ((multi-axial) or (multiaxial) or (multi axial))) with manipulator with movement	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/02/09 18:14
S117	8	((PETER) near2 (RIPPL). INV.	US-PGPUB; USPAT; USOOR	ADJ	ON	2009/03/17 10:37
S121	1389	(219/121.63).CCLS.	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2009/03/17 11:39
S122	115	S121 and robot with arm	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/17 11:39
S123	55	laser with weld and ((multi- axial) or (multiaxial) or (multi axial) or manipulator) with (velocity or speed or movement or motion)	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/17 14:17
S124	76	laser with weld and ((multi- axial) or (multiaxial) or (multi axial) or manipulator or robor or arm) with (velocity or speed)	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/17 14:23
S125	264	laser with weld\$3 and ((multi-axial) or (multiaxial) or (multi axial) or manipulator or robor or arm) with (velocity or speed)	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/17 14:34
S126	188	S125 not S124	US-PGPUB; USPAT; USOOR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/17 14:34

S131	824	(219/121.78).COLS.	US-PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2009/03/17 18:02
S132	2	S131 and robot with laser with ((compensat\$3 with motion) or (displac\$3 with motion))	US-PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/17 18:02
S134	16	("3888362" "4545713" "4563567" "4578554" "4623229" "4698483" "4707596" "4831232"). PN. OR ("5132887").URPN.	US-PGPUB; USPAT; USOCR	ADJ	ON	2009/03/17 18:12
S135	5	S134 and speed	US-PGPUB; USPAT; USOCR	ADJ	ON	2009/03/17 18:14
S136	204	(901/20).COLS.	US-PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	OR	OFF	2009/03/18 10:59
S137	57	S136 and (speed or velocity) with arm	US-PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/18 10:59
S140	190	(laser with weld\$3 with robot with arm)	US-PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/18 14:43
S141	71	S140 and (speed or velocity)	US-PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/18 14:44
S142	27	S140 and ((speed or velocity) with (head or arm))	US-PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/18 14:45

S143	42	S141 and (workpiece)	US_PGPUB; USPAT; USOCR; FPRS; EPO; JPO; DERWENT; IBM_TDB	ADJ	ON	2009/03/18 15:37
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